

B1
axis 12d connected to the additional rotational axis 12c for expanding and retracting in a direction in parallel with the attaching face of the robot wrist 1a, a second variable axis 12e connected to a distal end of the first variable axis 12d for expanding and retracting in a direction perpendicular--.

IN THE CLAIMS:

B2
Please CANCEL claims 2 and 10 and AMEND claims 1 and 9 as follows.

B2
1. (ONCE AMENDED) A robot system comprising:
a movable arm including a plurality of links and a wrist connected by joints and controlled by a robot controller having a software processing function; and
a tool unit mounted on said wrist at a distal end of said movable arm, and having an effecting end biased with respect to a final rotational axis of said wrist and directed to said final rotational axis.

B3
9. (ONCE AMENDED) A method of machining a cylindrical workpiece with a robot system comprising a movable arm including a plurality of links and a wrist connected by joints and controlled by a robot controller having a software processing function, a tool unit mounted on said wrist at a distal end of said movable arm, and having an effecting end biased with respect to a final rotational axis of said wrist and directed to said final rotational axis, said method comprising the steps of:

(a) arranging the workpiece so that a central axis of the workpiece is aligned with the final rotational axis of said wrist; and
(b) rotating said final rotational axis to perform machining on the workpiece.

REMARKS

In accordance with the foregoing, claims 2 and 10 have been canceled, and 1 and 9 have been amended. Claims 1, 3-9 and 11-16 are currently pending. No new matter is being presented.

Entry of the foregoing amendment is appropriate in response to the Final Office Action dated May 22, 2001, since these amendments clarify the claims in a manner which places this application in condition for immediate allowance or in better form for consideration on appeal, as described below.